

PATENT APPLICATION

**PWM-BASED MEASUREMENT INTERFACE FOR A MICRO-MACHINED
ELECTROSTATIC ACTUATOR**

Inventors:

David Horsley, a United States citizen
Residing at 1807 Spruce Street, Berkeley, CA 94709

William Clark, a United States citizen
Residing at 35624 Terrance Dr, Fremont, CA 94536

Robert Conant, a United States citizen
Residing at 2342 Shattuck Ave #212, Berkeley, CA
94704

Assignee:

Analog Devices, Inc.
Norwood, MA

Entity: Large Entity

Patent Application of

David Horsley, Robert Conant, William Clark
for

PWM-Based Measurement Interface For A Micro-Machined
Electrostatic Actuator

CROSS-REFERENCE TO A RELATED APPLICATION

This application is based on and claims priority from
Provisional application 60/245,249 filed November 1, 2000, the
entire disclosure of which is incorporated herein by
reference.

FIELD OF THE INVENTION

This invention relates generally to microelectromechanical
system (MEMS) devices. More particularly, it relates to
actuating and measuring the motion of a micro-machined
electrostatic actuator.

BACKGROUND OF THE INVENTION

Prior methods for capacitive position sensing of MEMS devices
have been focused towards inertial sensors such as
accelerometers and gyroscopes. These earlier techniques were
subject to the following disadvantages:

1. Sensitivity to low-frequency amplifier noise, such as
voltage offset and $1/f$ noise.
2. Sensitivity to capacitive "feed-through" of the drive
signal into the measurement signal. Many prior art MEMS
drive systems apply a small AC signal on top of a DC
drive voltage. The AC signal is used to measure the

capacitance of the MEMS device. Variations of the DC signal can be picked up by the capacitance sensing circuitry. Such pick-up is known as feed-through and is a form of noise. This noise may be significant since prior art capacitive sensing systems provide only a small amount of current for capacitive sensing.

3. Non-linear actuation force.

4. Analog interface. An analog interface adds to the complexity of the control circuitry.

SUMMARY OF THE INVENTION

The disadvantages associated with the prior art are overcome by embodiments of the present invention directed to methods and apparatus for varying and measuring the position of a micromachined electrostatic actuator using a pulse width modulated (PWM) pulse train. According to a method for varying the position of the actuator, one or more voltage pulses are applied to the actuator. In each of the pulses, a voltage changes from a first state to a second state and remains in the second state for a time Δt_{pulse} before returning to the first state. The position of the actuator may be varied by varying the time Δt_{pulse} . A position of the actuator may be determined by measuring a capacitance of the actuator when the voltage changes state, whether the time t is varied or not.

An apparatus for varying the position of a MEMS device may include a pulse width modulation generator coupled to the MEMS device an integrator coupled to the MEMS device and an analog-to-digital converter coupled to the integrator. The integrator may measure a charge transferred during a transition of a pulse from the pulse generator. The integrator may comprise an amplifier, an integrator capacitor,

a hold capacitor, a compensation voltage generator and three switches. The hold capacitor and integrator capacitor may be coupled to a MEMS device. The integrator capacitor, hold capacitor, and compensation voltage generator may be
5 selectively coupled to the amplifier by two of the switches. The MEMS device and hold capacitor may be selectively coupled to ground by a third switch.

Embodiments of the present invention that use a switching
10 integration technique are relatively insensitive to noise sources that have been problematic in the prior art.

Embodiments of the present invention use time-multiplexing to separate the measurement period from the driving period,
15 eliminating cross-talk between the drive and measurement signals.

Because embodiments of the present invention use a constant amplitude PWM pulse train, they are not subject to the
20 quadratic voltage to force non-linearity found in typical electrostatic actuation techniques.

Embodiments of the present invention use an entirely digital interface, rendering them compatible with modern digital
25 feedback control systems.

DESCRIPTION OF THE FIGURES

Fig. 1 is a schematic diagram of a circuit according to an
embodiment of the present invention;

Fig. 2 is a timing diagram illustrating pulsed actuation and
measurement according to an embodiment of the present
invention.

Fig. 3 is a schematic diagram of a switched capacitor integrator implementation according to an embodiment of the present invention.

5

DETAILED DESCRIPTION

It will be clear to one skilled in the art that the above embodiment may be altered in many ways without departing from the scope of the invention.

10

A circuit diagram according to an embodiment of the invention is illustrated in Fig. 1. The circuit consists of four stages - a pulse width modulation generator PWM, a MEMS device, represented as a variable sensor capacitor C_s , an integrator, and an analog-to-digital converter ADC. In the circuit, an input digital word D_{in} is first converted into a PWM pulse train by the PWM generator. The voltage pulse train includes one or more pulses characterized by a pulse width Δt_{pulse} . The voltage pulse train is applied to a MEMS devices, represented in Fig. 1 as a variable sensor capacitor, C_s , and the resulting current is integrated across an integrator having a capacitance C_i . The amplitude of the pulse train output from the integrator is simply the amplitude of the input pulse train scaled by the ratio of the sensor capacitance to the integrator capacitance, C_s/C_i . After a short time-delay t_s to allow the integrator to settle, the amplitude of each output pulse is sampled and converted into a digital signal using a sampling analog-to-digital converter ADC. To allow the integrator enough time to settle, the pulse width Δt_{pulse} is preferably greater than or equal to the sum of the integrator time-delay Δt_s and the ADC conversion time, Δt_{ADC} .

15

20

25

30

Fig. 2 depicts a graph of voltage versus time that illustrates capacitive sensing and pulse width modulation. The time-averaged drive voltage applied to the MEMS device may be changed by varying the pulse width Δt_{pulse} . If the pulse period T is shorter than the response time for the MEMS device, the device responds to the time averaged drive voltage. Thus, the position of the MEMS device may be varied by varying t_{pulse} , i.e., by varying the duty cycle of the pulse train. Preferably, the integrator measures charge transferred during a transition of the pulse, either from high to low or low to high. Therefore, a variation in Δt_{pulse} will not affect the capacitance measurement. Since the MEMS drive operates by pulse width modulation, a constant pulse height V_p may be used, simplifying the capacitance measurement. Furthermore, since the drive voltage V_p is used as the sense voltage, a large sense signal is available, which greatly enhances the signal to noise ratio of the capacitance measurement.

A switched-capacitor implementation of the integrator portion of the circuit is illustrated in Fig. 3. The circuit generally comprises an amplifier AMP, an integrator capacitor C_i , a hold capacitor C_h , a compensation voltage generator CVG and three switches S_1 , S_2 , S_3 . The hold capacitor C_h and integrator capacitor C_i are coupled to a MEMS device, represented by a variable capacitance C_s . The integrator capacitor C_i , hold capacitor C_h , and compensation voltage generator CVG are selectively coupled to the amplifier by two of the switches S_1 , S_2 . The MEMS device and hold capacitor C_h may be selectively coupled to ground by the third switch S_3 .

The advantage of this approach is that it is insensitive to low-frequency noise, such as amplifier offset and $1/f$ noise. A simple explanation of the circuit function is as follows. During the reset phase, all three switches are switched to

position 1. The amplifier becomes a voltage follower, and charges the hold capacitor, C_h , with the amplifier offset voltage. The compensation voltage generator CVG charges the integrator capacitor, C_i , with a compensation voltage V_c .
5 During the integration phase, the switches S_1 , S_2 , S_3 are all switched into position 2, in anticipation of the PWM pulse. The output voltage, V_o , is initially equal to the compensation voltage, V_c . Finally, the PWM pulse is applied to the sense capacitor, causing charge to flow through the sense capacitor.
10 A compensating charge flows through the integrator capacitor, and the output voltage becomes $(V_c - (C_s/C_i)V_p)$, where V_p is the amplitude of the input PWM pulse.

The principle by which the MEMS device represented by the
15 variable capacitance C_s is actuated may be described as follows. A PWM signal is generated by modulating the duty cycle of a fast pulse train with a slower base-band signal. In Fig. 1, the digital input D_{in} provides the base-band signal, while the fast pulse train is generated at a rate
20 equal to a counter's clock frequency divided by the maximum count, $f_{CLK}/2^N$.

The digital input word, D_{in} , is first converted into a PWM
25 signal that is input to the micro-machined actuator represented by the variable capacitor, C_s . The resulting current is integrated, and the result is sampled and converted into a digital word, D_{out} , by the analog to digital converter.

The position of the micro-machined actuator is only capable of
30 responding to the components of the PWM signal that are within its mechanical bandwidth. Provided that the fundamental PWM frequency is well above this bandwidth, the actuator behaves like a demodulator, recovering only the base-band signal.

For measurement purposes, because the pulse rate is much faster than the maximum base-band component, the sensor capacitance may be considered to be approximately constant for the duration of each pulse. In addition, to allow sufficient time for each measurement, the PWM pulse must be guaranteed high at the beginning of each pulse period and guaranteed low at the end of each period. Some of the dynamic range of the PWM input is lost as a consequence of this requirement, but it also effectively separates the measurement phase from the actuation phase, ensuring that the measurement signal of a particular sensor is not corrupted by cross-talk from adjacent devices. For example, in an array of devices, if the capacitances of the devices are measured on the rise of the pulses and since all of the drive pulses rise at the same time, any cross talk between different MEMS devices will be constant and, therefore, can be calibrated. Any cross-talk resulting from pulses falling at different times may be rendered irrelevant by simply not measuring capacitance when the pulses fall.

Because each PWM pulse has a constant amplitude, the amplitude of the voltage output from the integrator is directly proportional to this amplitude scaled by the ratio of the sensor capacitance to the integrator capacitance. For reduced sensitivity to temperature variations, this integrator capacitor may be a micro-machined capacitor whose temperature coefficient is matched to that of the sensor capacitor. Additionally, for reduced sensitivity to variations in the PWM pulse amplitude, the PWM voltage source may be used to generate a reference voltage for the ADC.

The various embodiments of the present invention may be applied to systems having multiple MEMS devices such as arrays of optical switching mirrors.